

### AMENDMENT TO SPECIFICATION

#### IN THE SPECIFICATION:

A marked-up copy of the changes to selected paragraph(s) is provided below. Please enter these changes to the specification in the record.

Paragraph spanning pages 10 and 11.

A preferred embodiment of the invention may use a following stage 3 as shown in Figures 2(a) and 2(b). The illustrated following stage 3 has two arms 8 that extend in the y direction and carry y-coils 9 for applying force in the y direction to the stage WS. Preferably, the y-coils 9 are along the length of arm 8. The arms 8 of the following stage 3 are supported on the base 1, such as by air bearings. The following stage 3 is driveable in the x-direction, such as by a linear motor installed on the reaction frame base. Such linear motor technology is well known to those skilled in the art. Such an x linear motor maybe used to drive the following stage 3 to follow the x motion of the wafer stage WS by utilizing a command signal (target position) that is the same as the command signal (target position) used by the x motor. The following stage may be controlled to maintain the gap between the stage WS and the following stage 3 based on the output of a gap sensor (not shown) that detects the information related to the gap. Allowing some relative motion in the x direction between the wafer W and following stage 3 reduces the acceleration required by the following stage 3, and therefore reduces the power consumption of the linear motor. The following stage 3 also carries two permanent magnets 13 (the other is not shown) which extend along the arms 8 in the y direction. These magnets 13 interact with each levitation magnet 10 on the wafer stage WS respectively to provide a levitation force to support the wafer stage WS weight with minimal or no power consumption. In Figure 2A, a wafer stage WS and accompanying components according to an exemplary form of the invention are shown in an exploded view. The bottom of the stage

**WS** contains permanent magnets **10** (such as levitation magnets) that interact with the magnets **13** on the following stage arms **8** to provide levitation force. The levitation magnets **10** and magnets **13** are shown in one possible configuration in the figure to provide a force on the stage to counteract gravity. Other possibilities also can be used, including air bellows, air bearings, or mechanical springs. Each of the x magnets **11** and y magnets **12** in the figures comprises an array of magnets with alternating polarities. For example, each x magnet array may consist of a plurality of parallel magnets arranged in the x direction as shown in Figure 6, with alternating parallel north magnets **22N** and south magnets **22S**.